AMENDMENTS TO THE CLAIMS:

This listing of claims will replace all prior version, and listings, of claims in the application:

Listing of Claims:

Claims 1-11 (canceled).

12. (New) A method for determining an accident risk of a first object (48, 52) with at least one second object (49; 53), comprising: determining the accident risk as a function of a collision probability and a hazard probability of the at least one second object (49, 53) in a predefined region (50, 55), and determining the collision probability and the hazard probability as a function of motions of the first and at least one second object.

13. (New) The method according to Claim 12, wherein an object class of the first and at least one second object are taken into account in determining the collision probability and the hazard probability.

14. (New) The method according to Claim 12, wherein the motion and the object class of the at least one second object are determined by way of a sensor suite (1), and the motion and the object class of the first object (48, 52) are retrieved from at least one data source.

15. (New) The method according to Claim 13, wherein the motion and the object class of the at least one second object are determined by way of a sensor suite (1), and the motion and the object class of the first object (48, 52) are retrieved from at least one data source.

16. (New) The method according to Claim 12, wherein the motion of the first object (48, 52) is defined by way of at least one current position and its velocity.

17. (New) The method according to Claim 13, wherein the motion of the first object (48, 52) is defined by way of at least one current position and its velocity.

18. (New) The method according to Claim 12, wherein the motion of the at least one second object (49, 53) is defined by way of at least one current position.

19. (New) The method according to Claim 13, wherein the motion of the at least one second object (49, 53) is defined by way of at least one current position.

20. (New) The method according to Claim 14, wherein the motion of the at least one second object (49, 53) is defined by way of at least one current position.

21. (New) The method according to Claim 16, wherein the motion of the at least one second object (49, 53) is defined by way of at least one current position.

22. (New) The method according to Claim 16, wherein the motion of the first object is additionally determined by way of at least one of its first longitudinal acceleration, first transverse acceleration, a first rotation angle and a first steering angle.

23. (New) The method according to Claim 18, wherein the motion of the at least one second object is additionally determined by way of its velocity relative to the first object and/or a second longitudinal acceleration and/or a second transverse acceleration and/or a second rotation angle.

24. (New) The method according to Claim 22, wherein environmental influences and/or a respective driving behavior are taken into account in determining the respective motion.

25. (New) The method according to Claim 23, wherein environmental influences and/or a respective driving behavior are taken into account in determining the respective motion.

26. (New) The method according to Claim 12, wherein at least one of an indication (4) and at least one signal to an actuator suite (35) are generated as a function of the accident risk.

27. (New) A method of using a control unit in a vehicle constituting an object in the method according to Claim 12.

28. (New) A method of using a restraint system (5) in a vehicle constituting an object in the method according to Claim 12.